

Abstract

A manipulating arm has an inward end configured as a sleeve for fitting around the forearm of an operator and an outward end having a tubular projection with an axially moving rod slideable therein. The rod has a hook at the outward end thereof for grasping razor ribbon, and is moveable between a retracted position and an extended position and is urged to the extended position by a spring. The distal end of the rod extends from the outward tubular member and is configured as a hook. The device includes a handle oriented perpendicular to the axis of the tube and a moveable trigger that can be grasped by the fingers of the operator while his palm is against the handle. Retracting the trigger retracts the rod within the tubular member, compresses the spring, and closes the hook of the claw around a piece of razor ribbon so that it can be positioned by the operator.